

**MANIPULATOR CONTROL UNIT****Publication number:** JP5228863**Publication date:** 1993-09-07**Inventor:** UENOHARA MICHIHIRO**Applicant:** TOKYO SHIBAURA ELECTRIC CO**Classification:**- International: **B25J9/06; B25J9/10; G05B19/18; B25J9/06; B25J9/10; G05B19/18; (IPC1-7): B25J9/06; B25J9/10**

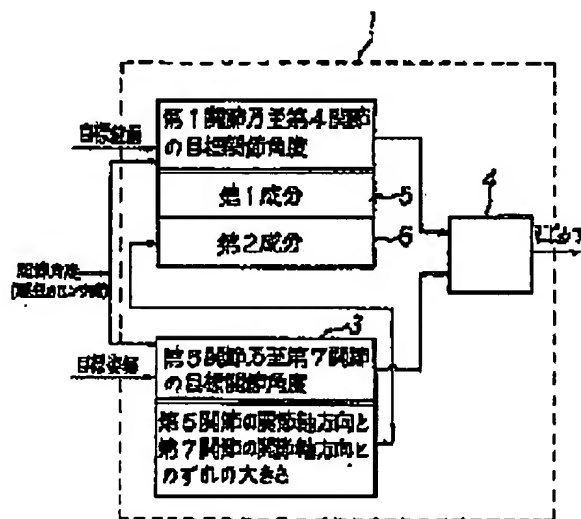
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**Application number:** JP19920033578 19920220**Priority number(s):** JP19920033578 19920220

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**Abstract of JP5228863**

**PURPOSE:**To facilitate a coordinate transformation finding a desired joint angle out of a desired position and a desired attitude by setting plural pieces of joints in each tip part to a relationship of roll-pitch-roll with one another, while adopting such a means that one intersection is set in each joint shaft of these joints and so on. **CONSTITUTION:**A control unit 1 of a manipulator with seven joints operates a desired joint angle of each of first to fourth joints at a position arithmetic unit on the basis of a desired position of an intersection being forced by a joint shaft of each of fifth to seventh joints. At this time, not only a first component 5 pertaining to a joint angle of each of first to fourth joints but also a second component 6 pertaining to the joint angle of each of the first to fourth joints for reducing the axial slippage of these first to fourth joints are operated together. In addition, on the basis of a desired attitude of a terminal attached to the seventh joint, the desired joint angle of each of the fifth to seventh joints is operated at an attitude arithmetic unit 3. Furthermore, on the basis of respective operational results of each arithmetic unit 3, the joint angle of each of the first to seventh joints is controlled by a joint angle control unit 4.

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